

WHAT IS CLAIMED IS:

1. A lower half body module of a bipedal walking robot comprising:

a base;

a right foot and a left foot;

a plurality of passive joints which are respectively provided on said base, said right foot and said left foot; and

parallel link mechanism portions which are respectively provided between said passive joint provided on said base and said passive joints provided on said right foot and between said passive joint provided on said base and said passive joints provided on said left foot.

2. A lower half body module of a bipedal walking robot according to Claim 1, wherein the three sets of said parallel link mechanism portions are respectively provided between said base and said right foot and between said base and said left foot.

3. A lower half body module of a bipedal walking robot according to any one of Claims 1 or 2, wherein said parallel link mechanism portions respectively have six degrees of freedom.

4. A lower half body module of a bipedal walking robot according to any one of Claims 1 to 3, comprising a plurality



of telescopic linear motion links which are provided between said base and said right foot and between said base and said left foot via said passive joints as links of said parallel link mechanism portions.

5. A lower half body module of a bipedal walking robot according to any one of Claims 1 to 4, wherein the links of said parallel link mechanism portions respectively include a linear motion type actuator as an actuator.

6. A lower half body module of a bipedal walking robot according to Claim 5, wherein said linear motion type actuator is provided at said base side of said linear motion link.

7. A lower half body module of a bipedal walking robot according to any one of Claims 1 to 6, comprising as said passive joints:

base side passive joints having overturned U-shaped base side upper couplings fixed to said base, overturned U-shaped base side lower couplings fixed to ends of said linear motion links respectively and connecting rotating portions which orthogonally and rotatably connect said base side upper coupling with said base side lower coupling; and

foot side passive joints having overturned U-shaped foot side upper couplings fixed to the other ends of said linear motion links respectively, foot side lower couplings rotatably



fixed to said feet respectively, and connecting rotating portions which orthogonally and rotatably connect said foot side upper coupling with said foot side lower coupling.